



**University of Idaho**

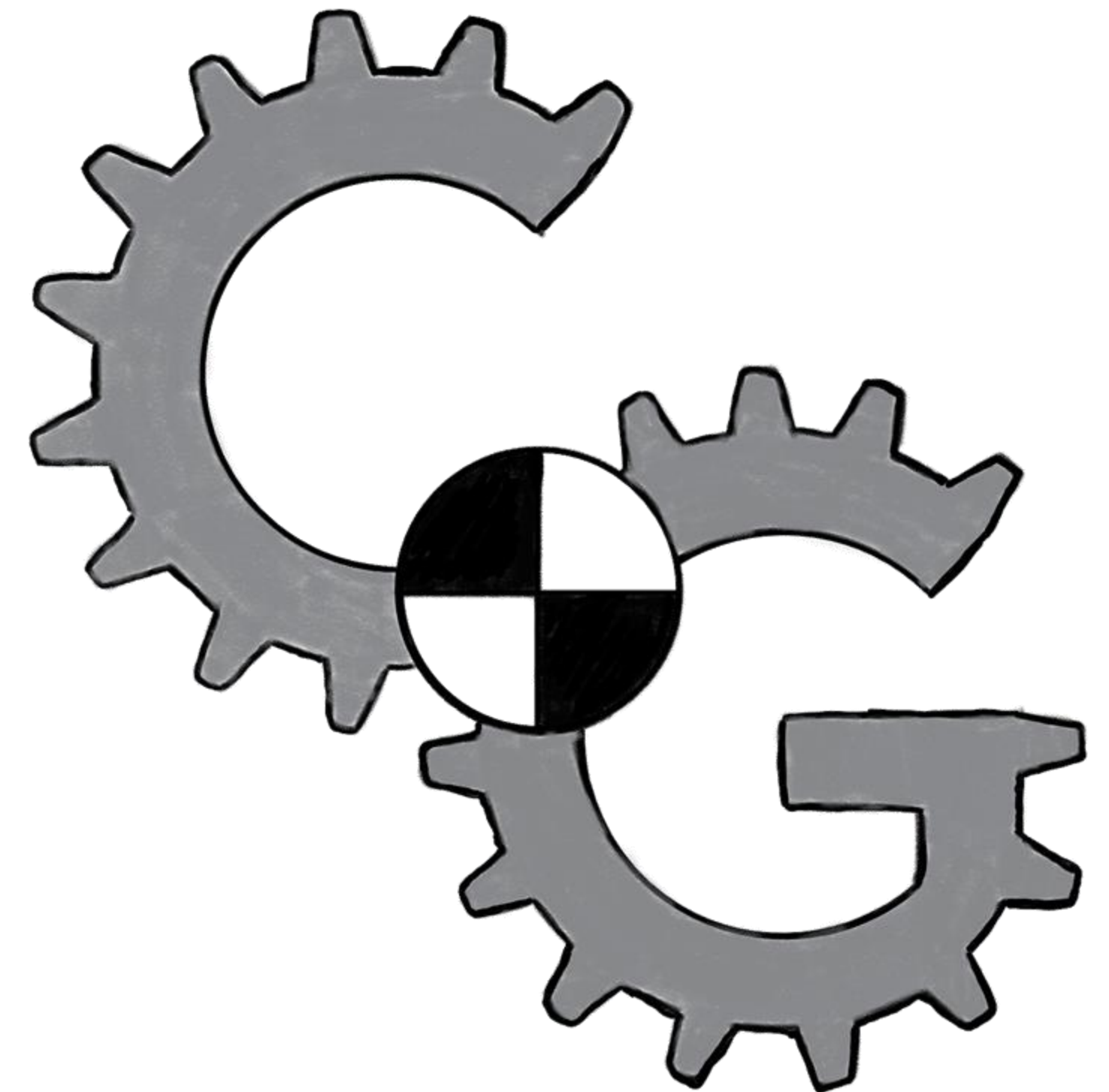
College of Engineering

# 3-AXIS CENTER OF GRAVITY INSTRUMENT

**KALEB CARTIER**

**KENDALL GRAY**

**ERIC SMEAD**



# INTRODUCTION



I Center of Gravity

I Natural Frequency of Entire Device

I Strain on Server Rack Mount Ears

# PROJECT REQUIREMENTS



## MECHANICAL

**I** Automatic

**I** 50 lbs

**I** Re-creatable

**I** Stretch goal: Vibration Test

## ELECTRICAL

**I** 120 VAC

## SOFTWARE

**I** Average Cartesian CG

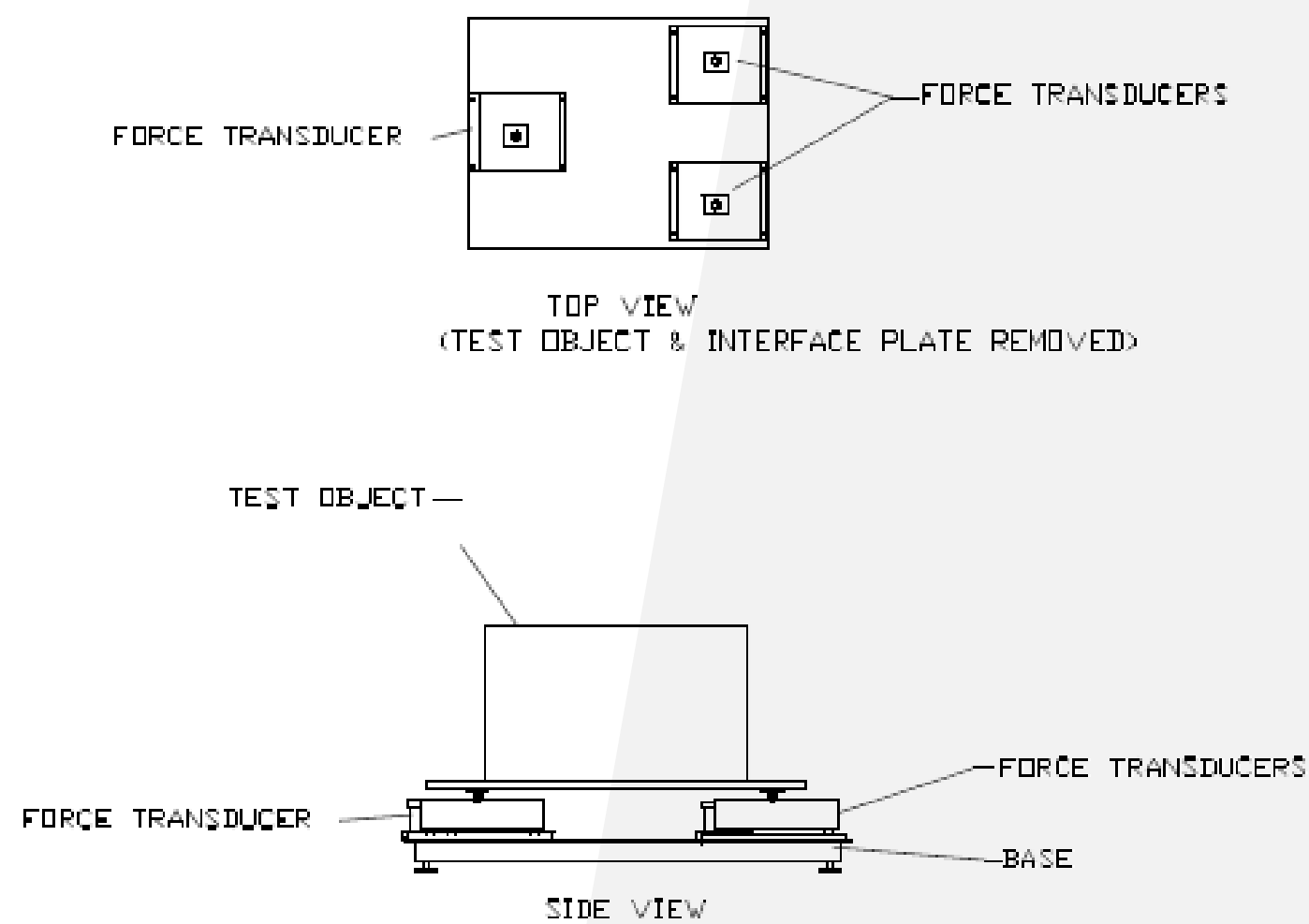
## ENVIRONMENTAL

**I** 60 to 85 °F

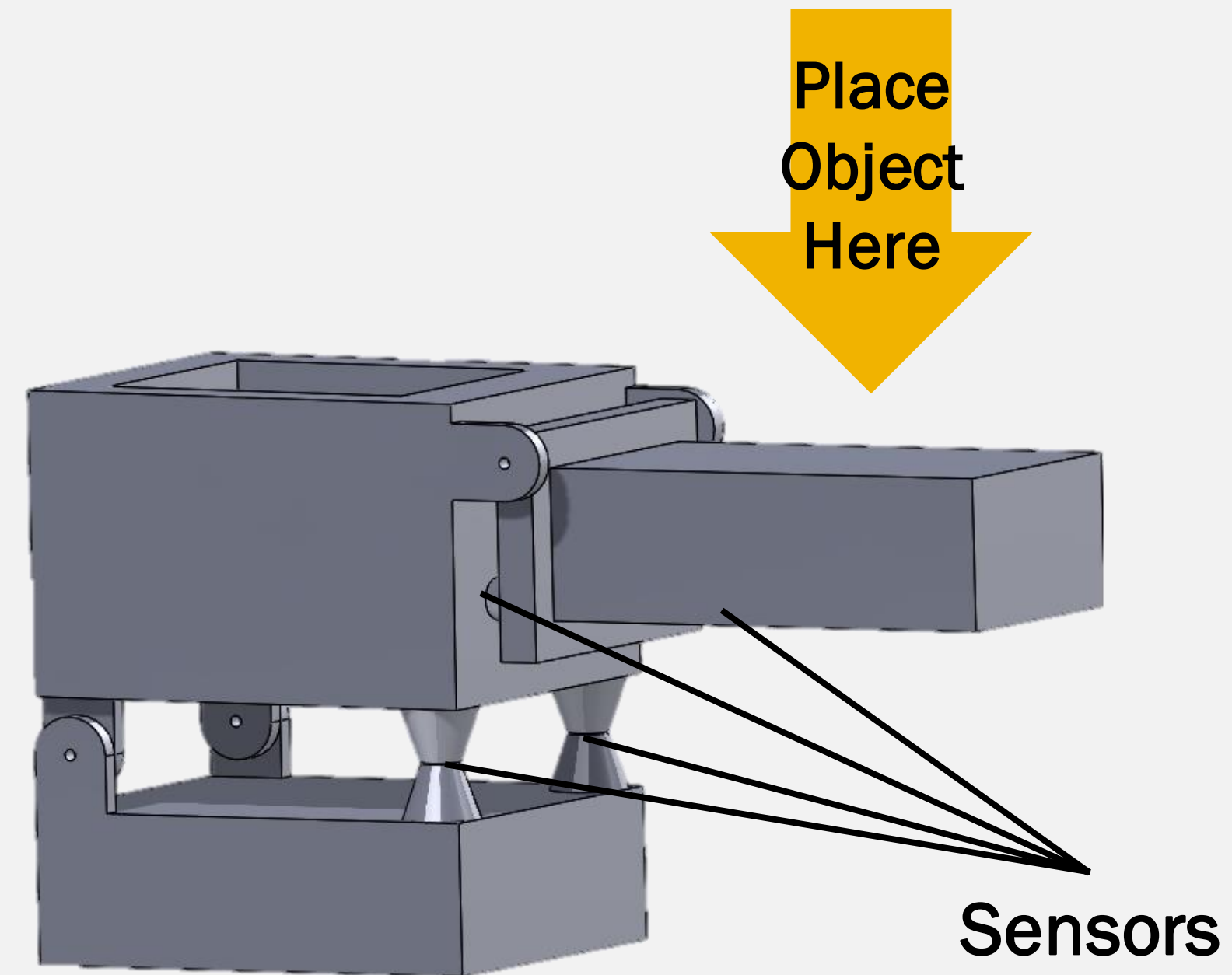
## COST

**I** \$1661

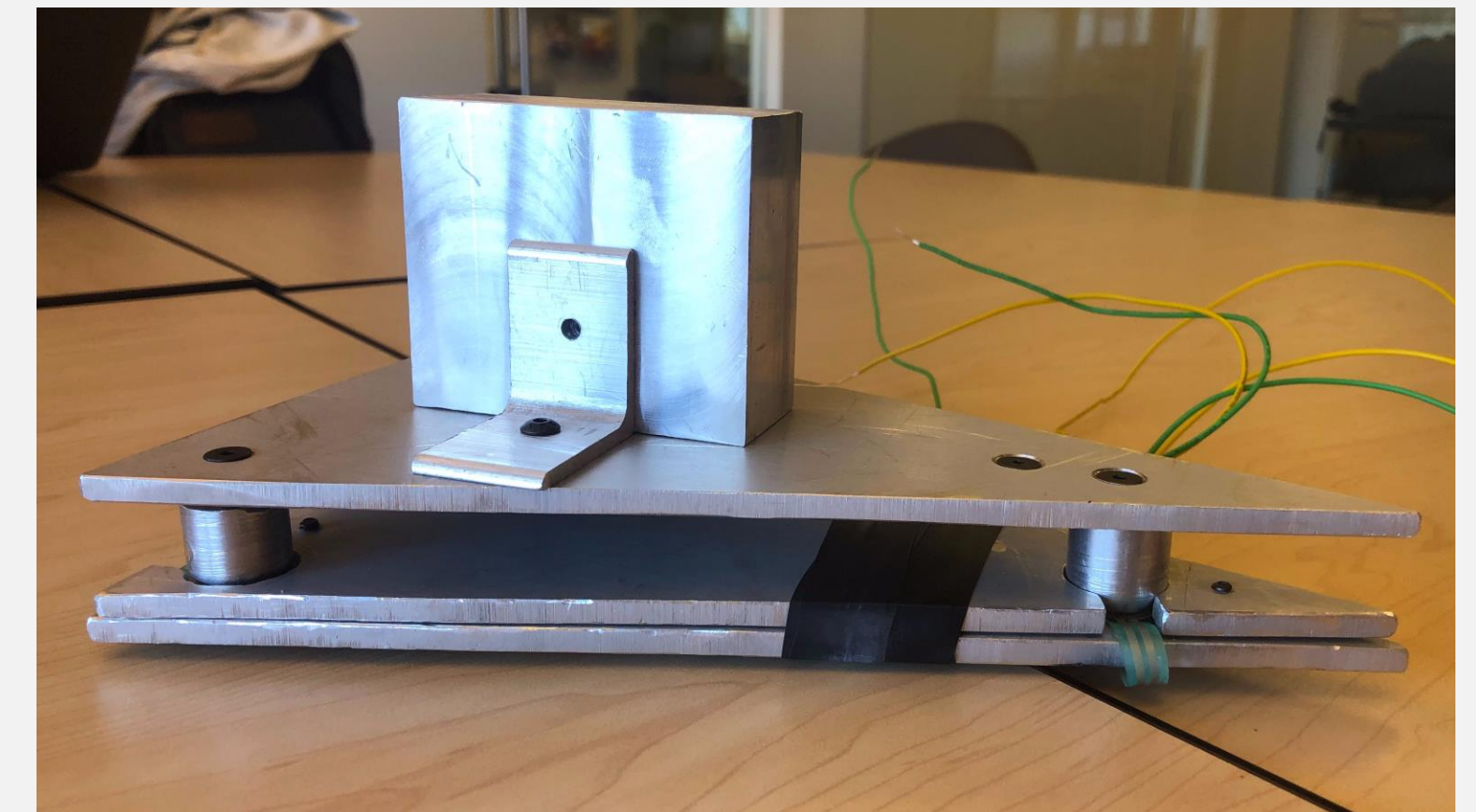
# FIRST SEMESTER



September 2018



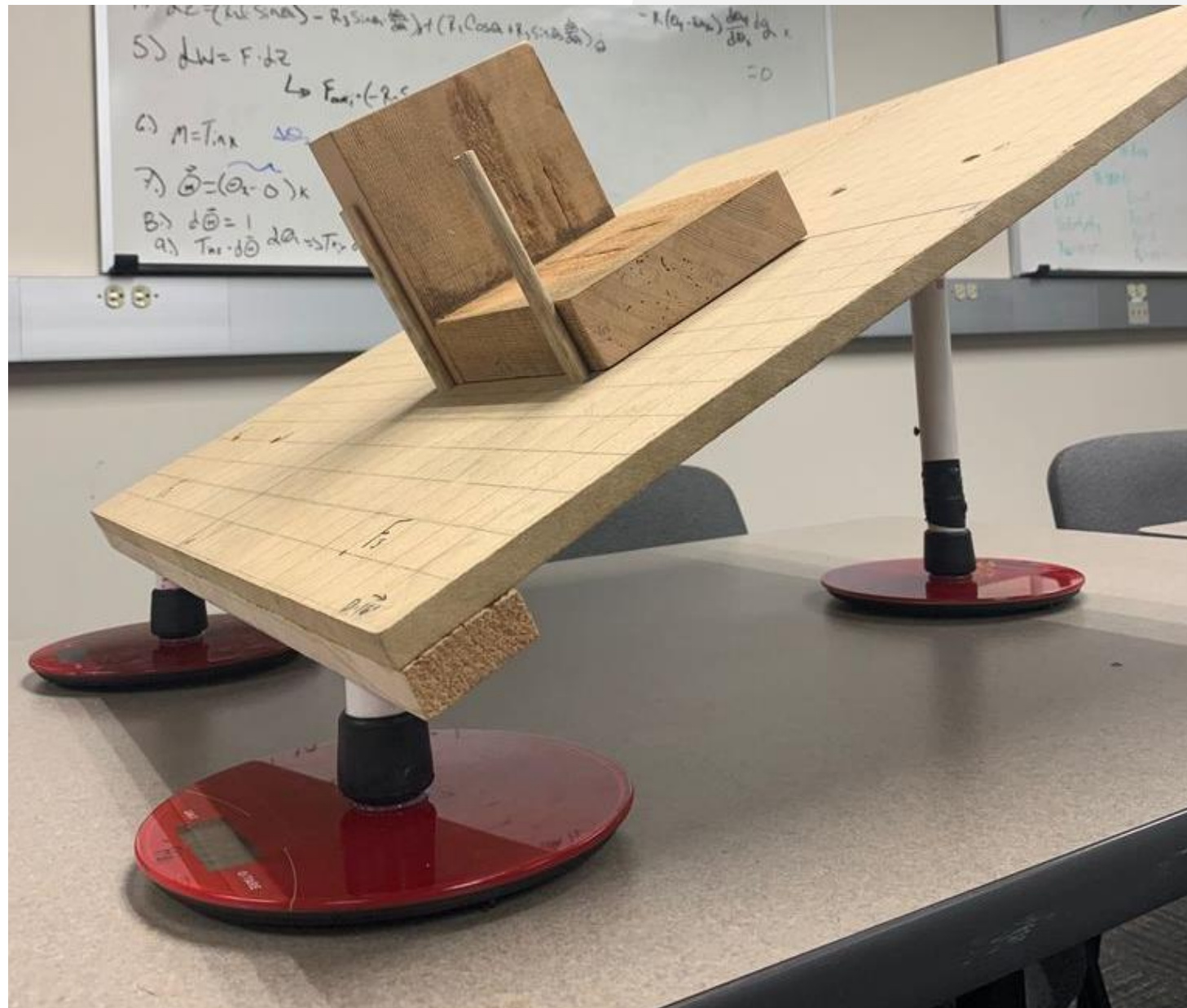
October 2018



November 2018



# SECOND SEMESTER



January 2019



February 2019



April 2019



# TESTING PROTOTYPE PROGRESSION



First Design Iteration



Second Design Iteration



Final Design Iteration



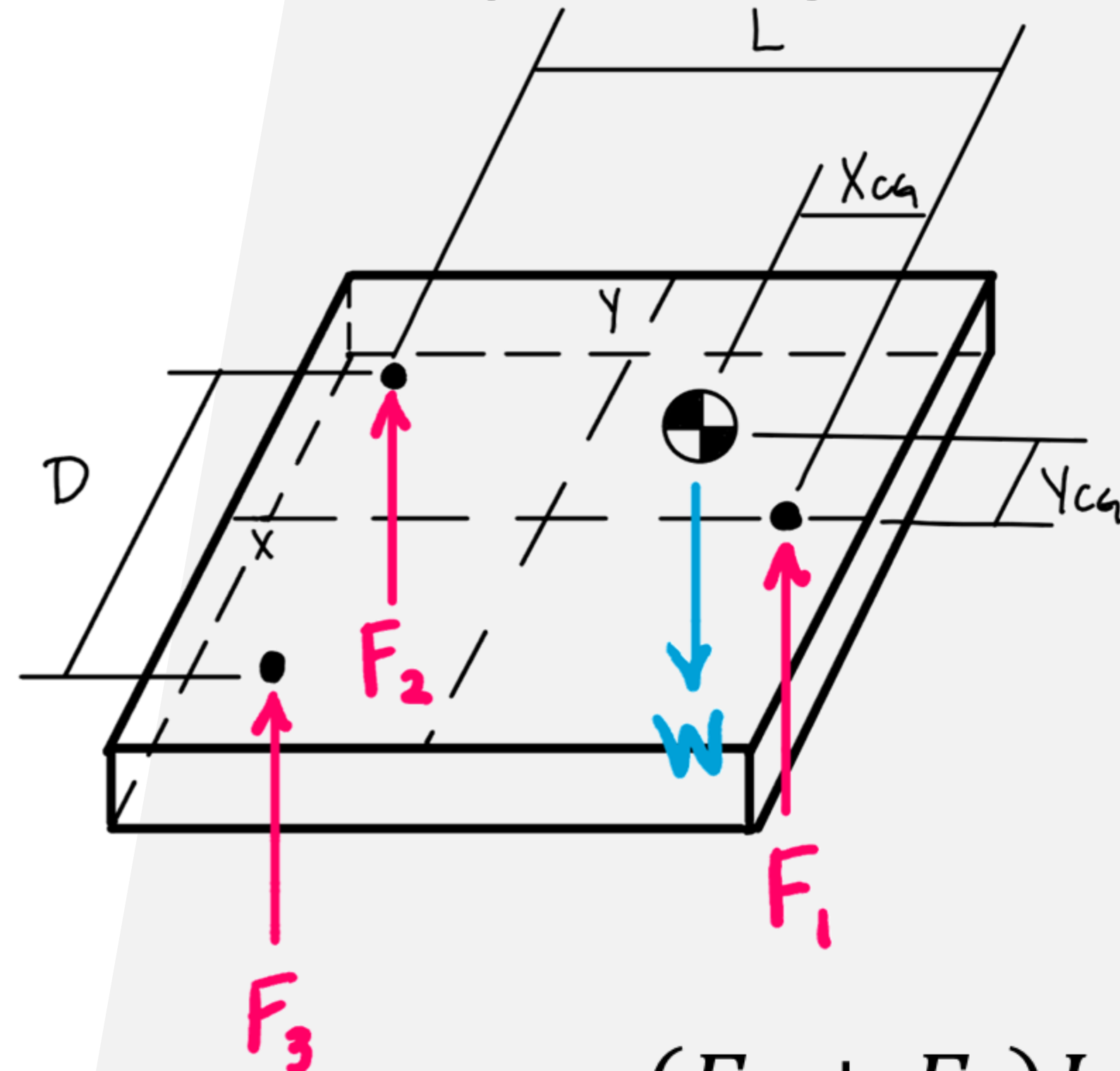
# CG TESTING DATA



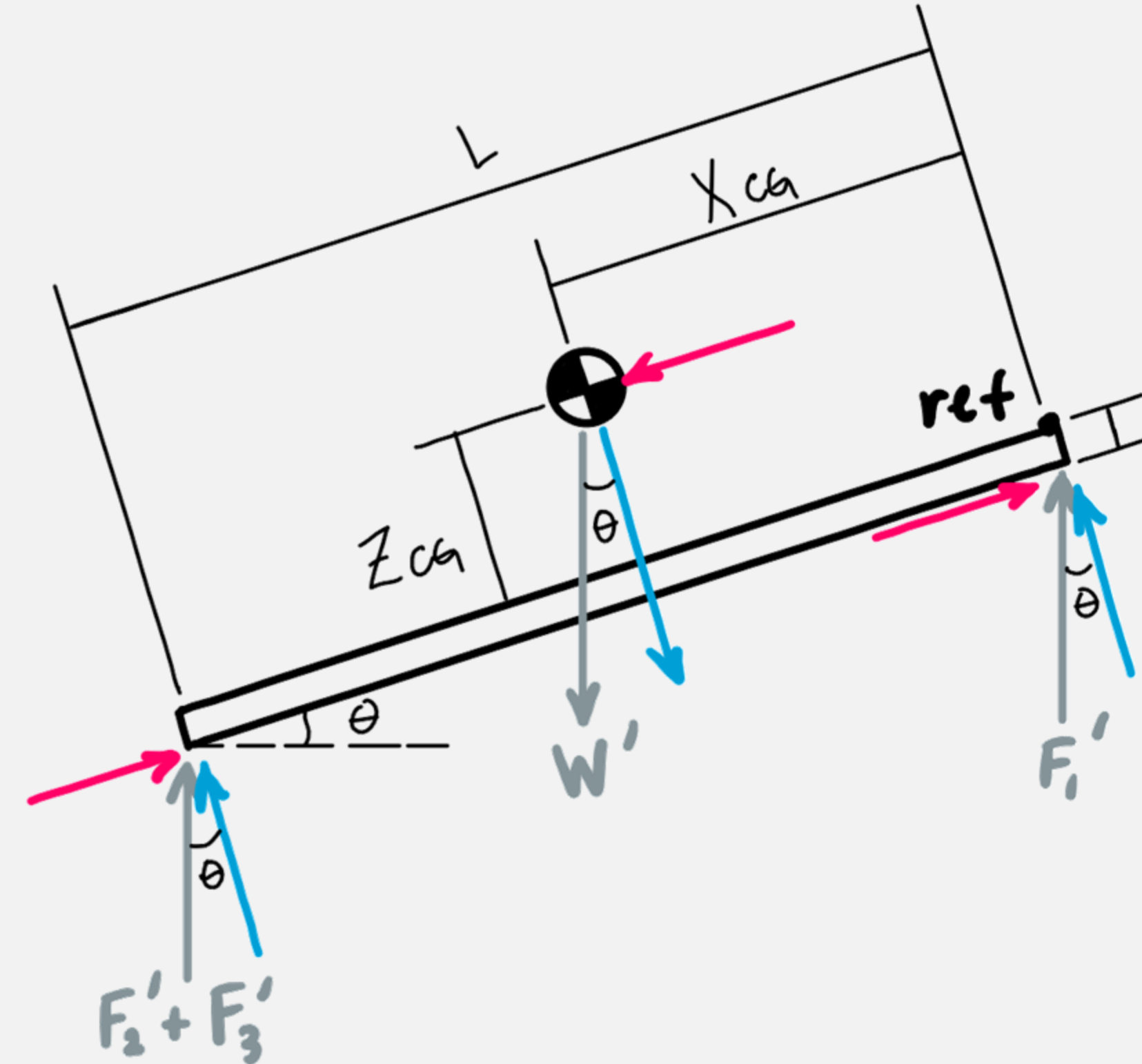
	Measured	Actual	Percent Error
X	2.7"	2.75"	1.85%
Y	2.6"	2.56"	1.54%
Z	1.8"	1.9"	5.56%



# HOW IT WORKS



$$X_{CG} = \frac{(F_2 + F_3)L}{W}$$



$$Y_{CG} = \frac{(F_2 + F_3)D}{2W}$$

$$Z_{CG} = \frac{(F_2' + F_3') \cos \theta * L - W' (\sin \theta * t + \cos \theta * x_{cg})}{W' \sin \theta}$$



# FINAL DESIGN



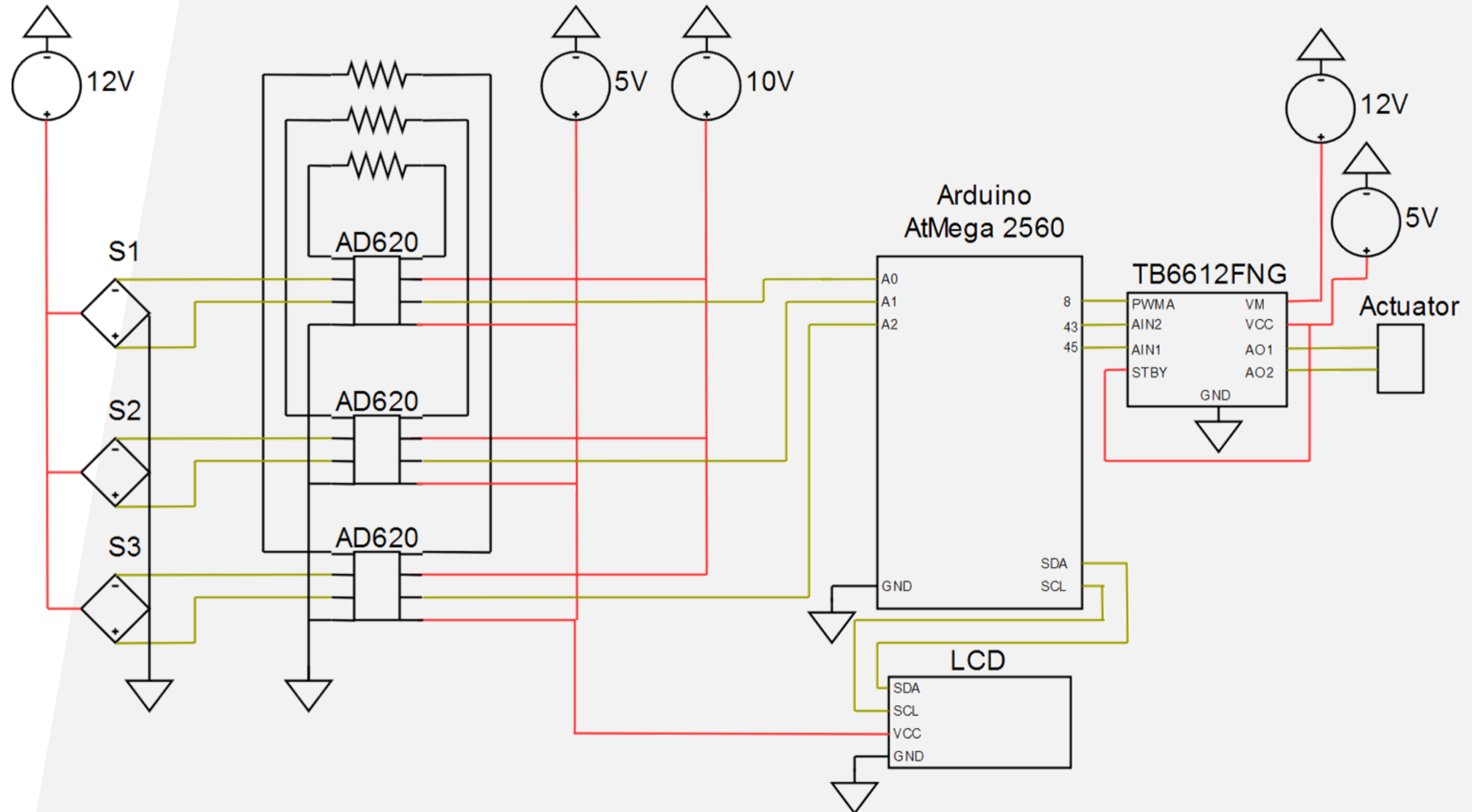
# GENERAL SPECIFICATIONS



<b>Weight</b>	67.8 lbs
<b>Size</b>	24" x 24" x 33"
<b>Maximum Angle</b>	32°
<b>Sensors</b>	S-type Load Cell, 25 lb limit each
<b>Actuator</b>	150 lb ; 12 in stroke ; 0.37 in/sec Duty Cycle: 25% (5 min on/15 min off)

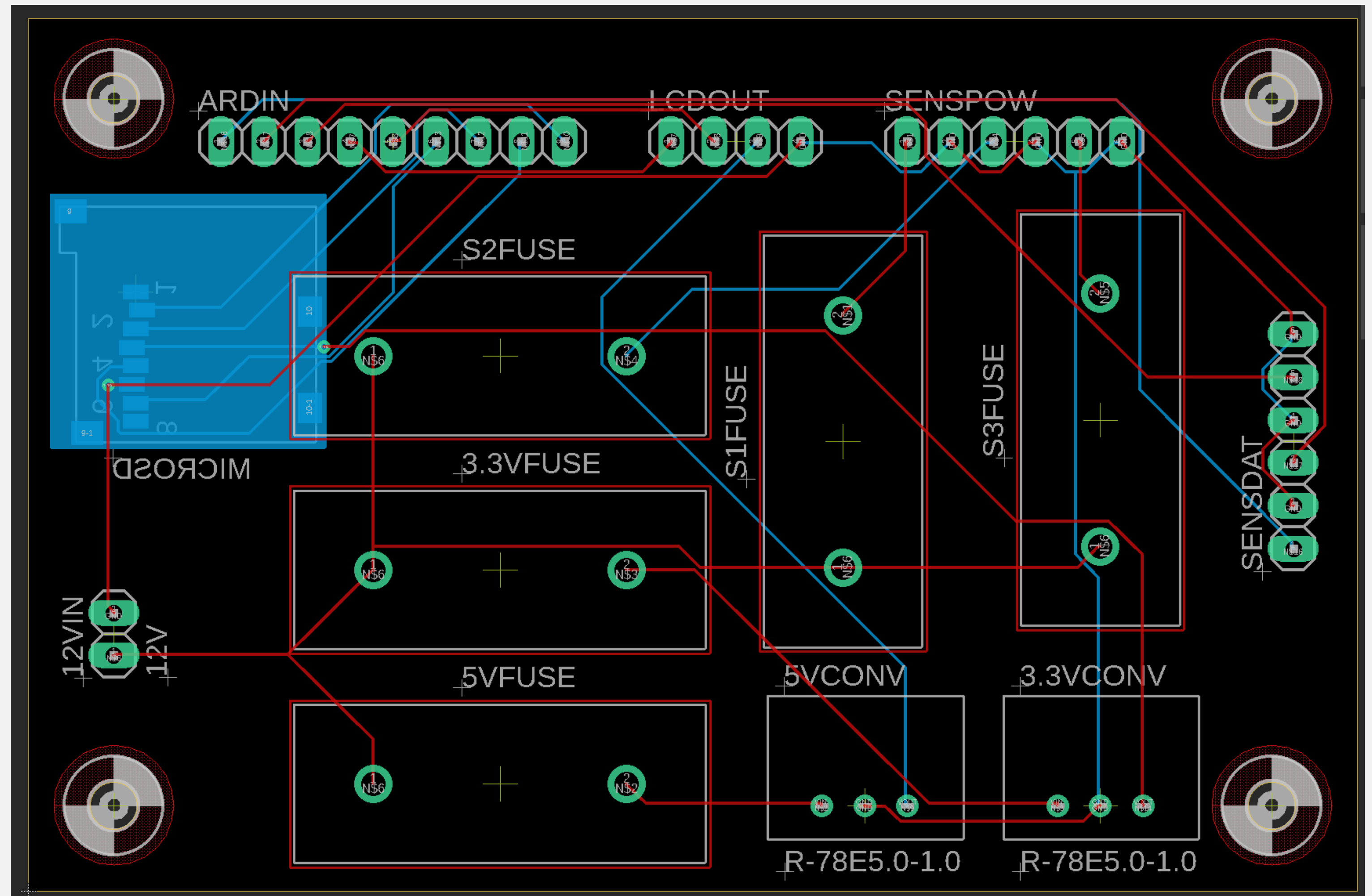


# ELECTRICAL DESIGN



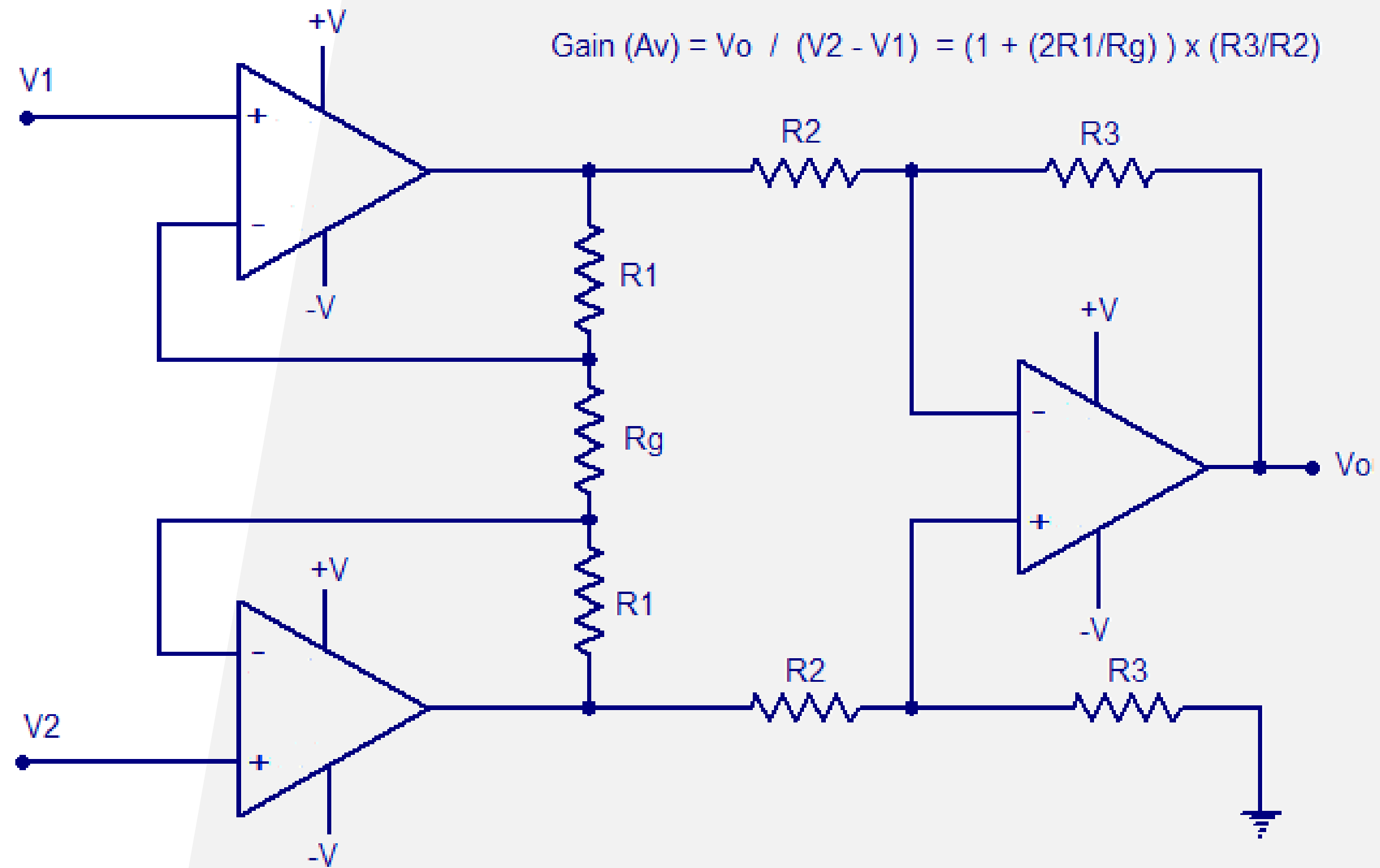
# PROBLEMS

- PCB
- Shorting/Power
- LCD Display
- Amplification





# AMPLIFICATION

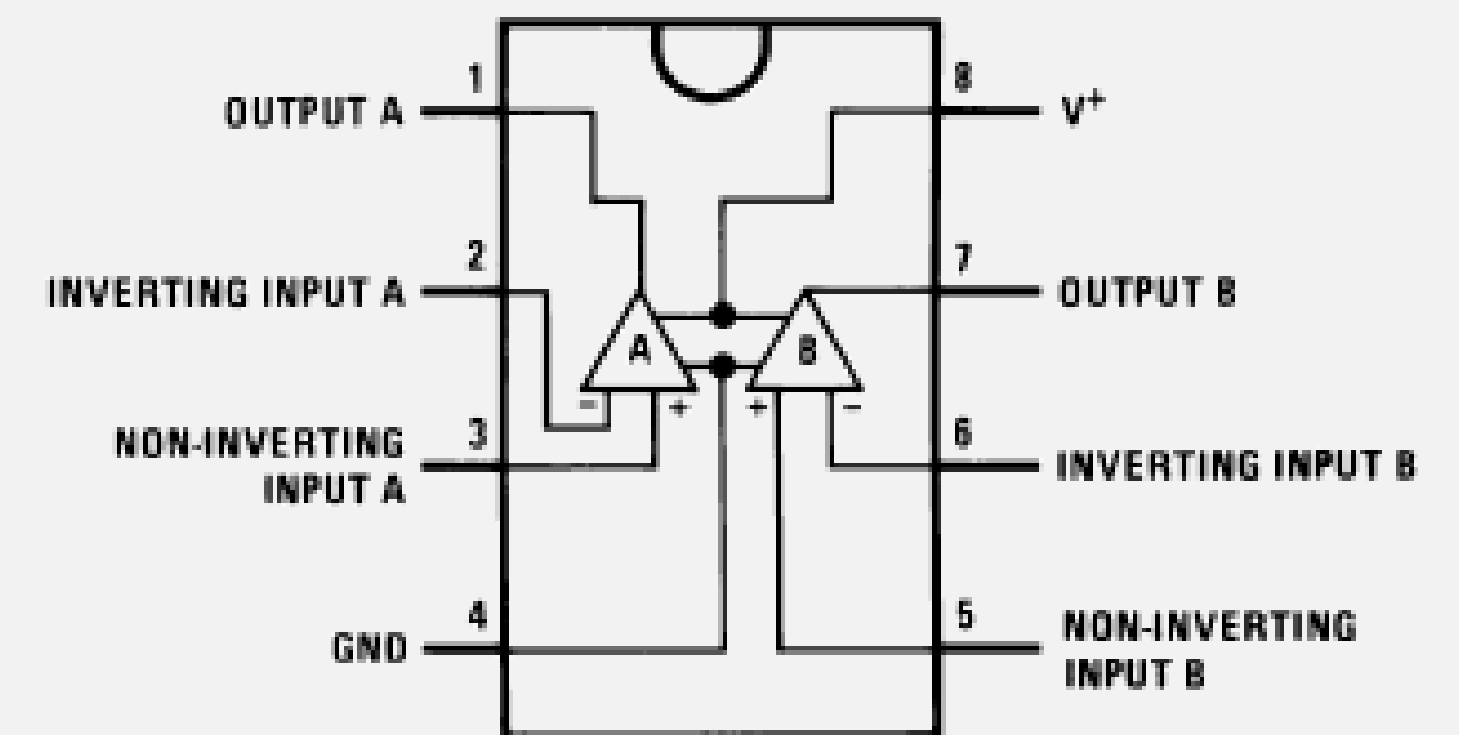


INSTRUMENTATION AMPLIFIER

[www.circuitstoday.com](http://www.circuitstoday.com)

## LM358AN

D, P, and NAB Package  
8-Pin SOIC, PDIP, and CDIP  
Top View



# OPERATION INSTRUCTIONS

1. Turn on using red switch
2. Push button to start calibration
3. Relay is placed on top of device
4. Button is pushed again to start CG calculation
5. CG data is output to the LCD screen
6. Turn off the device



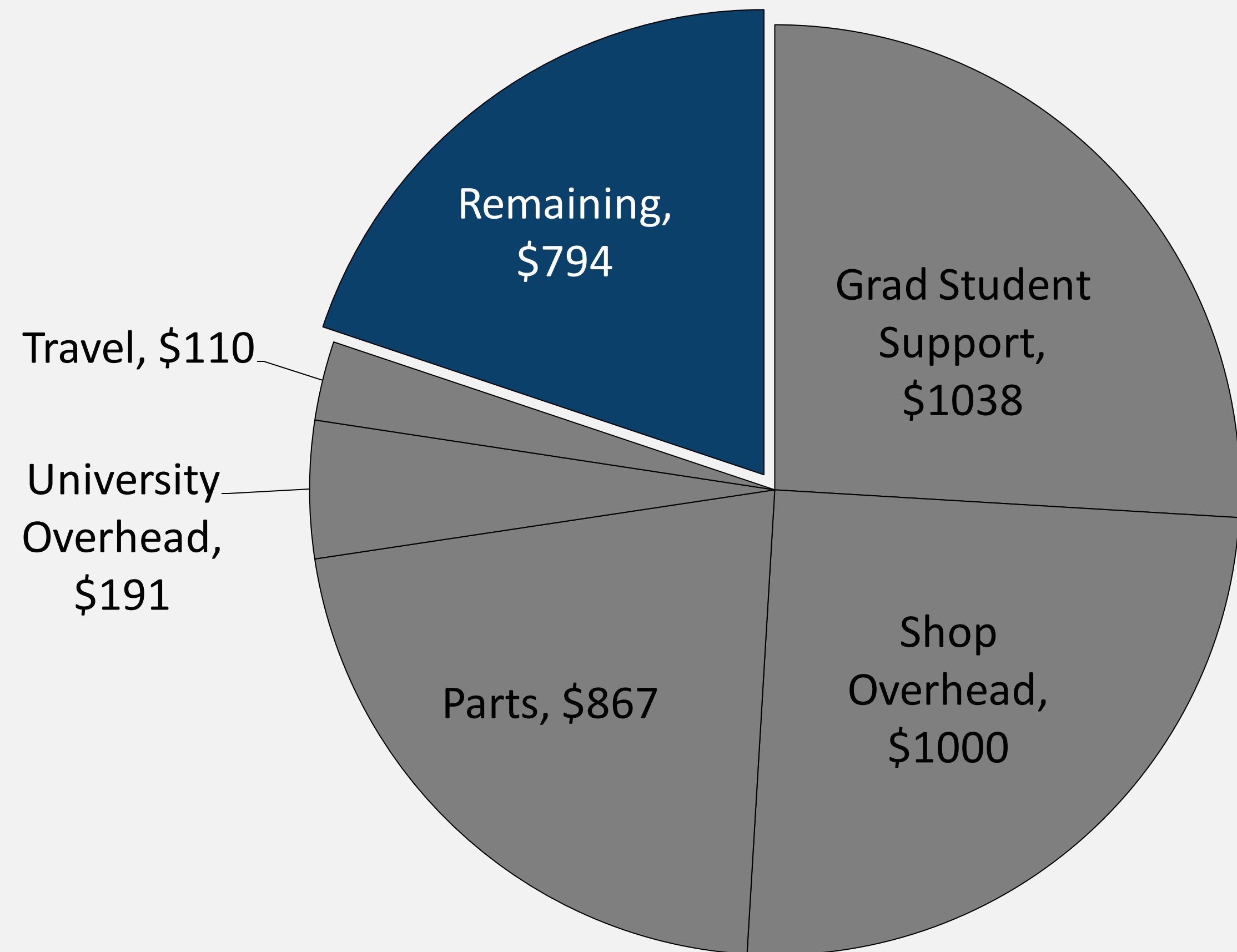


# DEVELOPMENT COST



Budget Spending Distribution	
Grad Student Support	\$ 1038
Shop Overhead	\$ 1000
University Overhead	\$ 191
Parts	\$ 867
Travel	\$ 110

Cost Distribution + Remaining



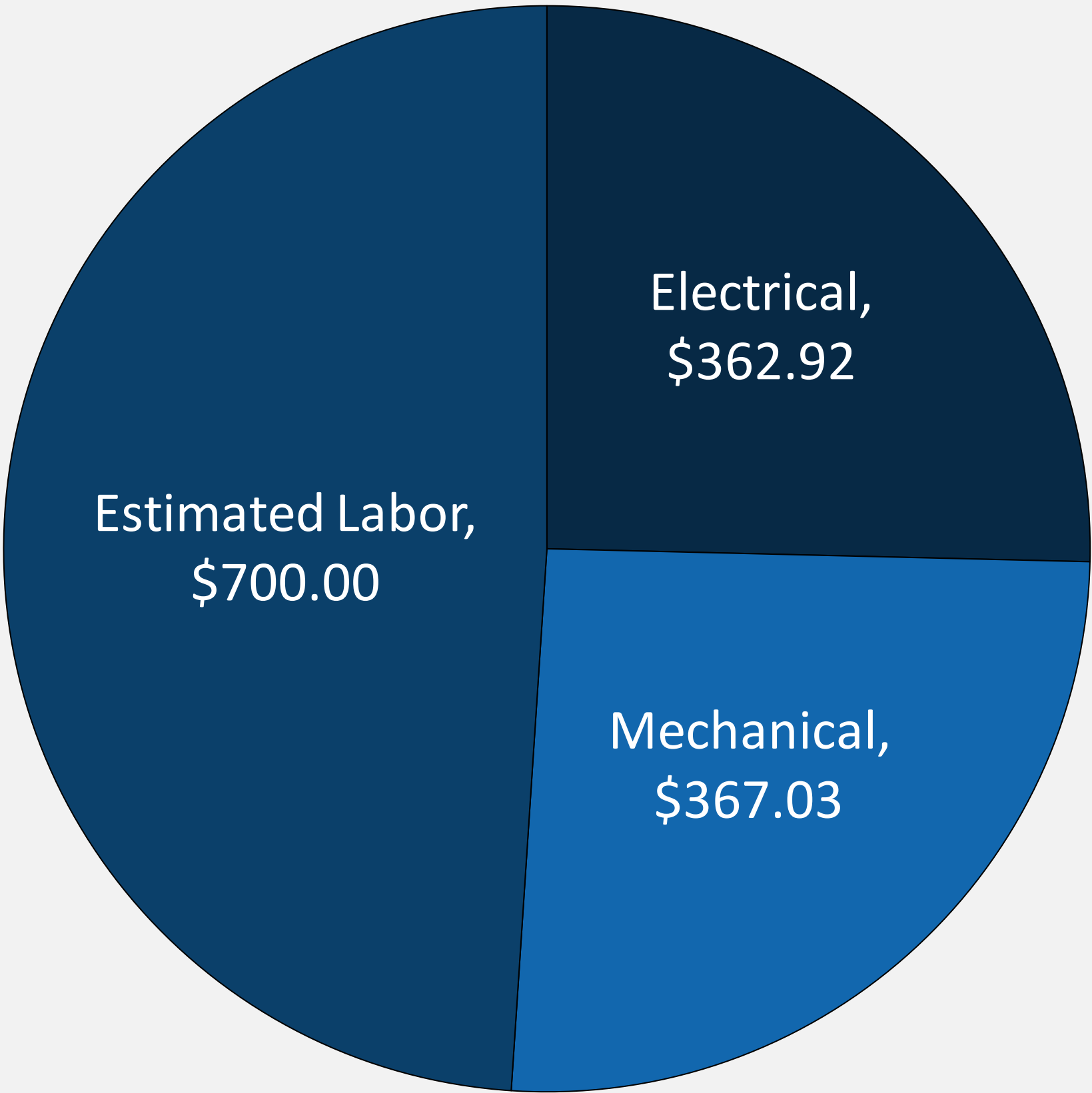


# ESTIMATED COST OF GOODS



<u>Electrical</u>	<u>\$362.92</u>	<u>Mechanical</u>	<u>\$367.03</u>	<u>Other</u>	<u>\$700.00</u>
Arduino AtMega 2560	\$13.99	LA Mounting Bracket	\$16.84	Estimated Labor	\$700.00
Arduino LCD	\$12.99	Aluminum Stock	\$241.42		
Breadboard Jumper Wires	\$5.99	UHMW Plastic Bars	\$17.34		
Linear Actuator	\$116.86	Screws and Nuts	\$4.18		
Microchip	\$7.74	Other Fasteners	\$62.24		
Op-amps	\$65.91	Rubber Tubing	\$25.00		
S-type Load Cells	\$68.95				
PCB Samples	\$18.67				
MlcroSD Card Port	\$4.99				
MicroSD Card	\$2.92				
DC Converters	\$10.04				
Fuse Holder Blocks	\$5.70				
Glass Fuses	\$4.31				
Push Button	\$5.89				
Power Supply	\$10.99				
Power Socket	\$6.99				

Parts/Service Type Cost Distribution



# CHANGES FOR NEXT ITERATION

- Better sensors
- More accurate dimensioning during manufacturing
- Server rack mount rails instead of vertical bars
- Guard rails for sensor tracks



# WHAT WE LEARNED

- Assembly can reveal more design issues
- Shop work takes longer than expected
- Getting sensors earlier
- Combine things one at a time
- Hope for the best, prepare for the worst

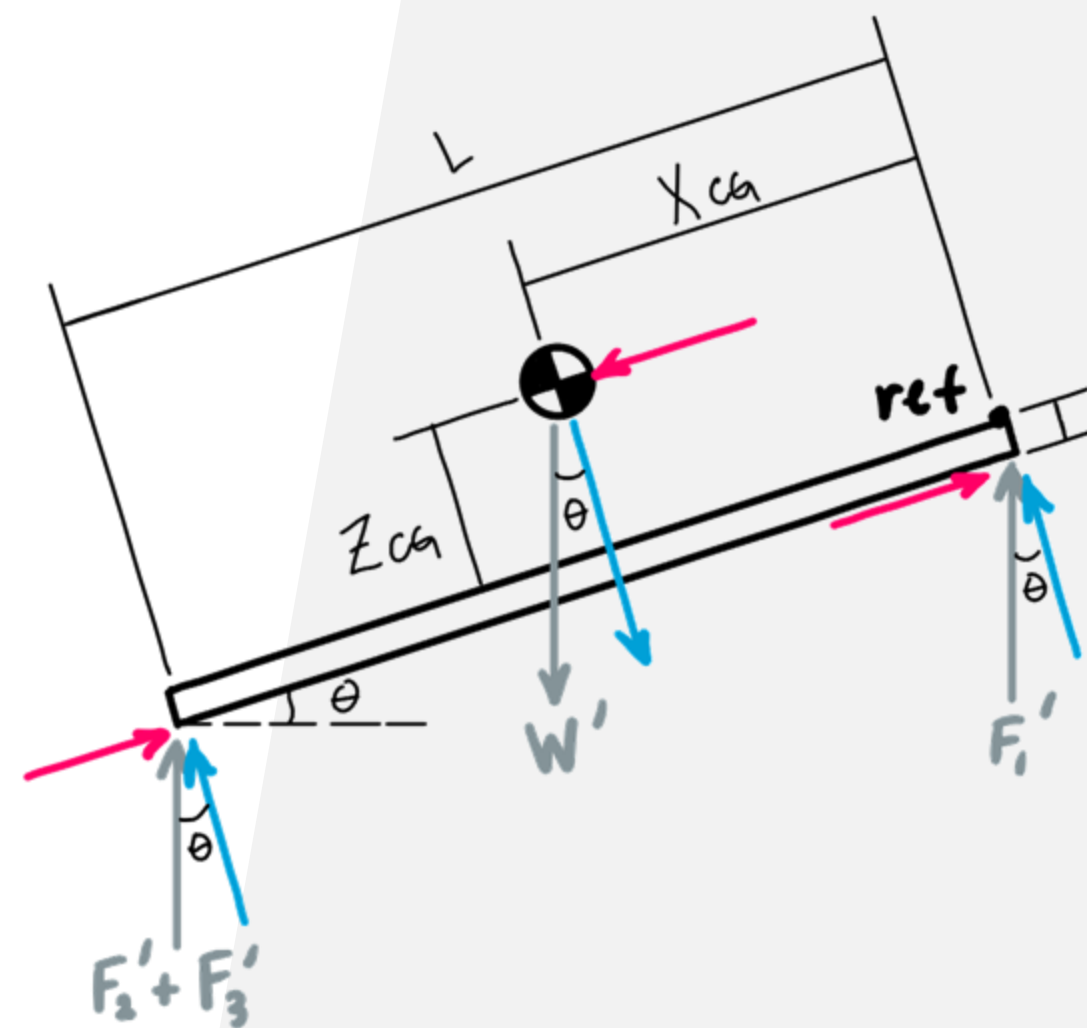
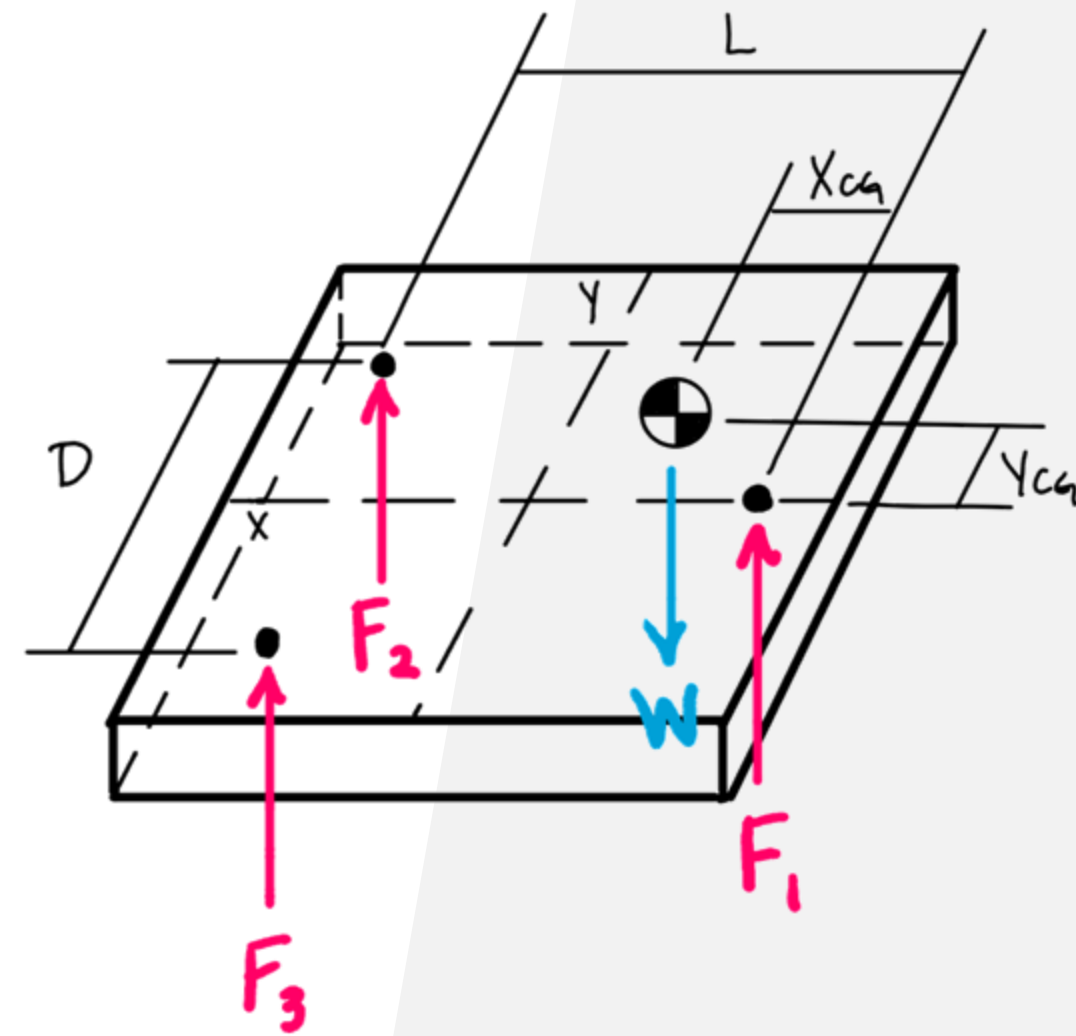


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# VARIABLE DEFINITIONS



$X_{CG}$  = Center of gravity x – coordinate

$Y_{CG}$  = Center of gravity y – coordinate

$Z_{CG}$  = Center of gravity z – coordinate

$L$  = Distance between  $F_1$  and  $F_2$  in x direction

$D$  = Distance between  $F_2$  and  $F_3$  in y direction

$t$  = Top plate thickness

$\theta$  = Angle of tilt

$W = F_1 + F_2 + F_3$  = Total object weight\*

$F_1$  = Force exerted on sensor 1\*

$F_2$  = Force exerted on sensor 2\*

$F_3$  = Force exerted on sensor 3\*

\*Prime superscript indicates tilted orientation

# MECHANICAL PARTS COST BREAKDOWN



Aluminum Stock		Screws		Nuts		Other Fasteners	
1/4 x 24 x 24 Plate	47.72	1/4-20, 1.25" (7x)	1.53	1/4-28	0.05	Ball Joints	13.53
1/2 x 24 x 24 Plate	84.08	1/4-28, 1.5" (4x)	1.54	8-32 (4x)	0.30	Clevises	27.72
1/2 x 24 x 16 Plate	61.94	8-32, 0.5" (8x)	0.51	6-32	0.07	Brackets	2.50
1 x 2 x 2.5 Bar (2x)	17.02	6-32, 2.5"	0.20			Zip Ties	7.47
1/4 x 3/4 x 10 Bar (2x)	14.86					ZT Mounts	10.85
1.125D, 1.5L Rod	7.01					Cotter Pin	0.17
3/8 x 0.049, 2" Tubing	8.79						



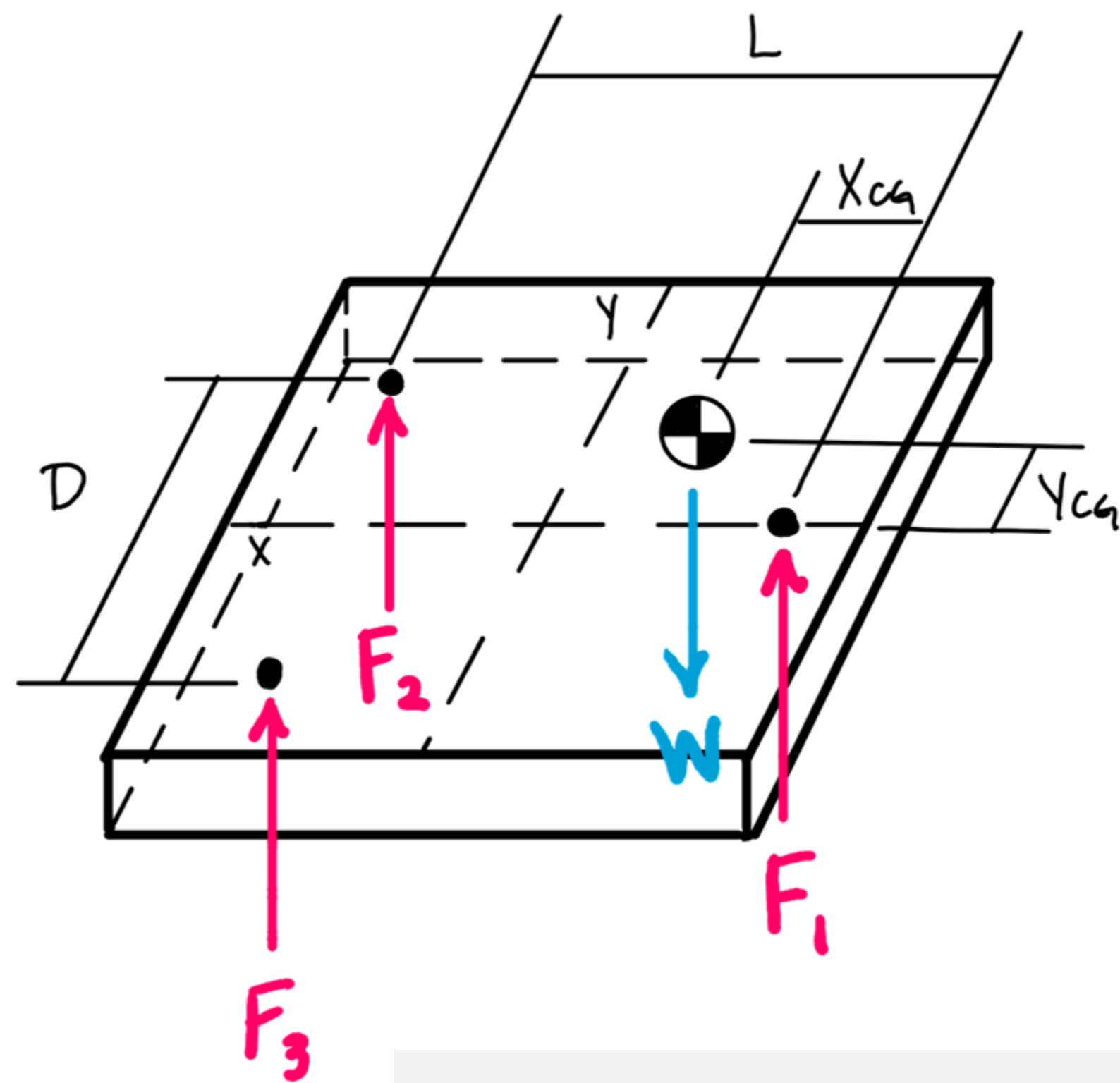
# BUDGET SPENDING ON PARTS

Expense Items	2018-2019							
	September	October	November	December	January	February	March	April
Mechanical Parts								
Particle Board						\$ 7.50		
LA Mounting Bracket						\$ 16.84		
Aluminum Plates						\$ 230.89		
UHMW Plastic Bars							\$ 17.34	
Ball Joints							\$ 13.53	
Clevises							\$ 27.72	
Zip Ties								\$ 7.47
Zip Tie Adhesive Mounts								\$ 10.85
Rubber Tubing								\$ 25.00
Electrical Parts								
Arduino AtMega 2560		\$ 20.94						\$ 13.99
22lb Force Sensors		\$ 45.87	\$ 45.00					
Arduino LCD			\$ 12.99					
Breadboard Jumper Wires			\$ 5.99					
Linear Actuator						\$ 116.86		

# BUDGET SPENDING ON PARTS (CONT.)

Linear Actuator						\$ 116.86		
Microchip						\$ 7.74		
S-type Load Cells						\$ 68.95		
PCB Samples							\$ 18.67	
MicroSD Card Port							\$ 4.99	
MicroSD Card							\$ 2.92	
DC Converters							\$ 10.04	
Fuseholder Blocks							\$ 5.70	
Glass Fuses							\$ 4.31	
Push Button							\$ 5.89	
Power Supply							\$ 10.99	
Power Socket							\$ 6.99	
Amplifiers								\$ 65.91
Other								
3-D Printer Filament		\$ 29.99						
Toy Balancing Eagle								\$ 5.13

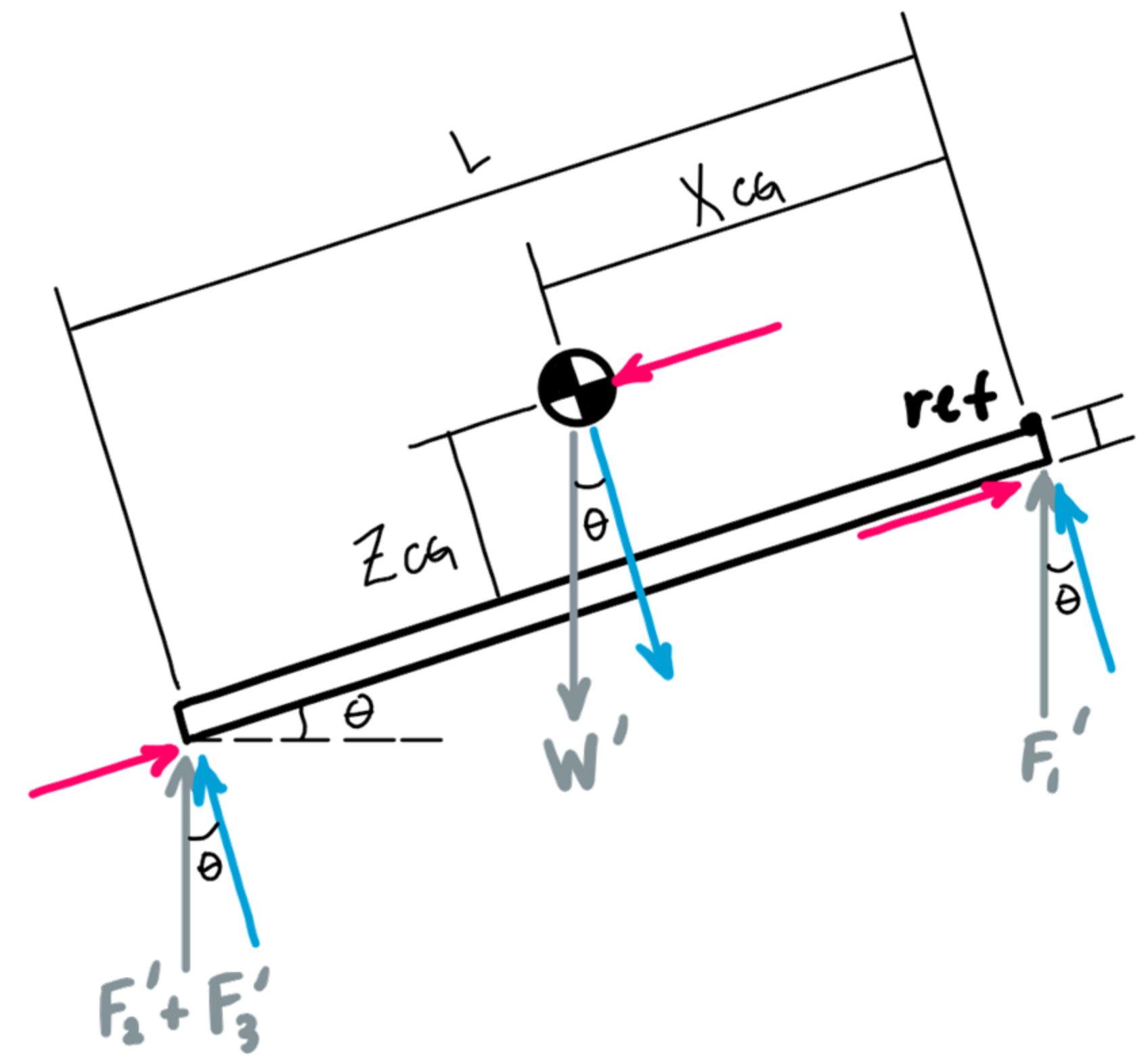




$$X_{CG} = \frac{(F_2 + F_3)L}{W}$$



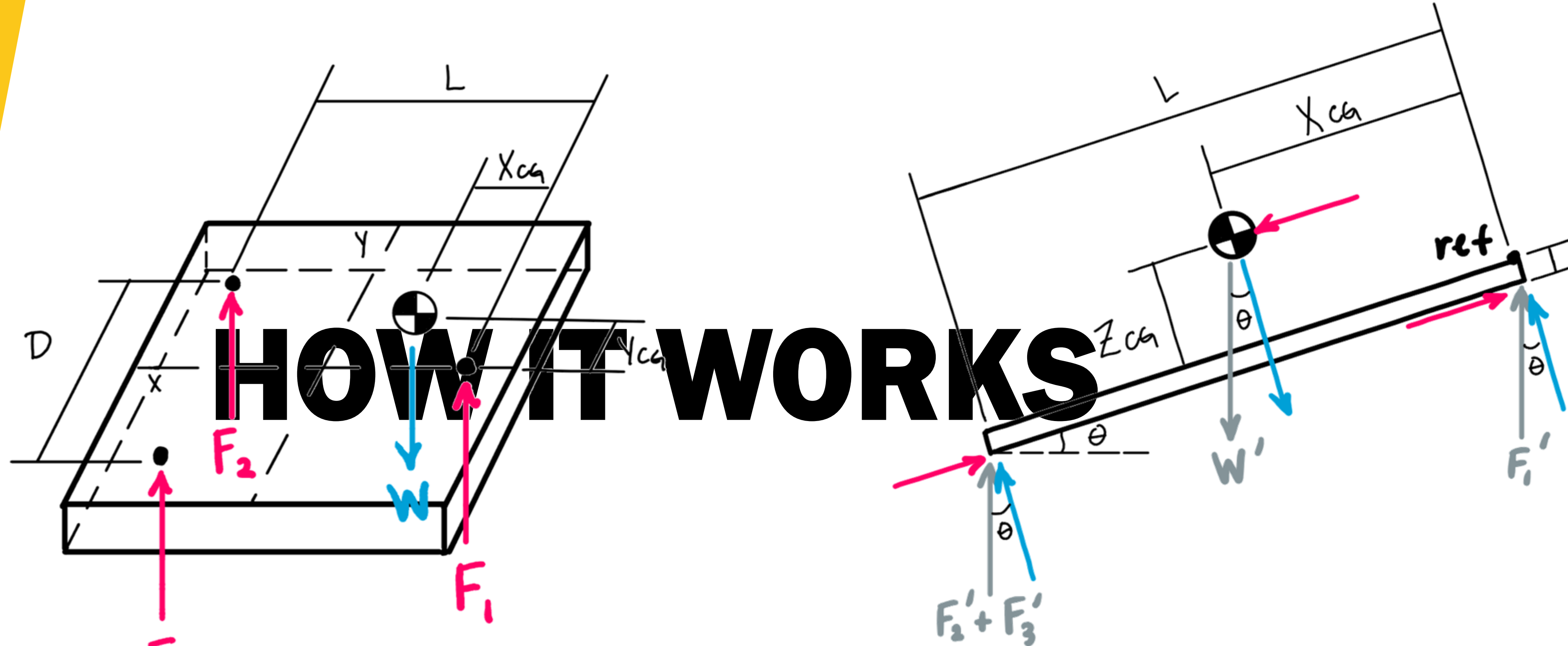
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$$Y_{CG} = \frac{(F_2 + F_3)D}{2W}$$

## HOW IT WORKS

$$Z_{CG} = \frac{(F_2' + F_3') \cos \theta * L - W' (\sin \theta * t + \cos \theta * x_{cg})}{W' \sin \theta}$$



$$X_{CG} = \frac{(F_2 + F_3)L}{W}$$

$$Y_{CG} = \frac{(F_2 + F_3)D}{2W}$$

$$Z_{CG} = \frac{(F'_2 + F'_3) \cos \theta * L - W' (\sin \theta * t + \cos \theta * x_{cg})}{W' \sin \theta}$$